Remarks

1. Page 23 is added to the pages that are amended. On page 20, an additional correction is made on the previous amendment page 20, due to a typing error. Both marked up and clean copies of pages 20 and 23 are provided.

2. No new matter is introduced by this change.

Respectfully submitted,

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suspensions 13 and 14 cover two quadrants 20 and 21 of the disk 33 area concurrently and can move independently. Data track 23a is one set of innermost tracks of the outer most set of tracks, that are located on the outer 1/2 area of the disk 33. Similarly data track 22b is one set of the inner most tracks that are within the inner 1/2 area of disk 33. The limited designated distances 17 and 17a are assigned to each actuator members of the pair actuator 13. Similarly, the actuator pairs 14 move within the designated limited distances of 18 and 18a. The opposite quadrants 20 and 21 that the pair of actuators 13 and 14 function upon, are the areas over which the system has concurrent R/W capability. Pair actuator arms and suspension 13 moves on linear stationary micro-rail 16. Similarly, the pair of actuator arm and suspension 14 moves on linear stationary micro-rail 15. Also shown is one of the flexible printed circuit (FPC) electronic wiring 13c and 13d connection that connects wiring ~~13a~~ to the drive electronics board.

With reference to figure 4, depicted in perspective view are both pairs of wing shaped actuators-carriage arms 13 and 14 that move upon the stationary micro-rails 16 and 15 respectively. This pair of actuator arms 13 enables access to two different quadrant areas 20 and 21 of the disks 33 and 34 concurrently. Due to the pair of actuators 13 and 14, a multitude number of inner tracks 22 and a multitude number of outer tracks 23 are read/written concurrently with only 1/2 of a revolution of the disk 33 and 34. The flexible printed circuit (FPC) electronic wiring board 13c and 13d that have a wiring pattern that have signal lines that connect the wing shaped actuator-carriage arms 13 and 13a and R/W heads 26, 27, 28, 26b, 27b, 28b (all not shown) to the drive electronics board. The reference center line C indicates the inner limit of the outer actuator 13-one member of the pairs that is over the outer 1/2 tracks-of the disk 33, this is the inner limit reaching border for the outer one of

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of invention is 40b. The magnetizable layer of the invention disk 40 is 40a.

With reference to figure 10, the actuator arm 13 moves upon micro-rail 16. The R/W transducer heads 26 and thin pads 43 are affixed to said actuator arm 13 and makes R/W heads 26 to fly upon disk surface 33a with a constant fly height ~~40~~ 39. The actuator 13 moves as its lower cylinder rail member part 13c moves within the cylindrical cavity 16h (not shown in this drawing) of micro-rail 16.

With reference to figure 11, the actuator 13 and stationary micro-rail 16 are depicted as these are disassembled. The internal surfaces are such that-enclosed by the micro rail cavity 16h- the cylinder rail member 13c of the actuator 13, moves only linearly-force applied by the analog voice coil motor does not make the rail member 13c to make any upward-vertical, downward or horizontal deflections, since the rail member 13c of actuator 13 is a micro-cylinder and fits exactly to said cavity-as depicted by four sides 16d, 16e and 16f, 16g of micro rail 16. The internal surfaces of cylindrical cavities 16h of said rail 16 have internal and external surface coating 16c that minimizes friction to near zero. Such material is called near zero frictional coating (NFC) invented at Argonne laboratories. Other friction eliminating material could be applied if such is more suitable for this extremely thin layer application that involves very small components. For the form factors of 1 inch and lower, the system would enter the realm of nano-technology, as components and coatings would be proportionally smaller and thinner. R/W transducer heads 26 and thin pads 43 are seen below pairs of actuator-carriage arm 13.

With reference to figure 12, depicts in plan view, how the wing shaped pair of actuator arms 13 are able to be positioned over-at a stationary mode and receive a set of data tracks 22 and 23 at an acute angle theta-relative to the actuator arm 13. The connection and

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